Claims

1. A remote controlled robotic manipulator for manipulating a moving object comprising a motion sensor for sensing motion of a region of an object to be manipulated, and a controller for locking motion of the robotic manipulator relative to the region of the object based on the sensed motion, wherein controller further controls for which region of the object the motion sensor senses motion.

2. A manipulator as claimed in claim 1 in which the motion sensor is controllable by a human user.

3. A manipulator as claimed in claim 2 in which the motion sensor is controllable by tracking the visual fixation point of the user.

4. A manipulator as claimed in claim 3 in which the user views a remote representation of the object.

5. A method of identifying a visual fixation point of a user observing a stereo image formed by visually superposing mono images comprising the steps of presenting one mono image to each user eye to form the stereo image and tracking the fixation point of each eye.

6. A method as claimed in claim 5 in which the three dimensional position of the visual fixation point is determined.

7. An apparatus for identifying a fixation point in a stereo image comprising first and second displays for displaying mono images, a stereo image

presentation module for visually super-posing the mono images to form the stereo image and an eye tracker for tracking the fixation point of each eye.

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